

Amendments to the Specification:

Please replace the paragraph beginning on page 1, line 6, with the following rewritten paragraph:

The present application is a divisional application of co-pending U.S. patent application Serial No. 10/121,304, filed April 12, 2002, which is a continuation-in-part of U.S. patent application Serial No. 09/912,914, filed July 25, 2001, which in turn claims the benefit of U.S. provisional application Serial Nos. 60/285,442 filed April 19, 2001, and 60/283,490 filed April 12, 2001, all of which are incorporated herein. ~~The present application is a continuation-in-part of U.S. patent application Serial No. 09/912,914, filed July 25, 2001, which is incorporated herein.~~

Please replace the paragraph beginning at page 8, line 4, with the following rewritten paragraph:

FIG. 12A is a detail view of the sensor and support structure of the web tracking system of FIG. 11, ~~with~~ and FIG. 12B is an enlarged view of the sensor;

Please replace the paragraph beginning at page 10, line 19, with the following rewritten paragraph:

A flexible coupling 162 connects a given threaded rod 116 to a corresponding servo motor 165 with an attached gear head (not shown) having a drive shaft 167 joined to the flexible couplings 162. There is one servo motor 165 for each threaded rod 116, e.g., in the illustrated apparatus there would be six motors 165. Each servo motor 165 is connected to an operating computer 170 and an external power source ~~470~~ 171. The apparatus 108 could have any number of rods and/or motors, depending on the number of operating units used. All rods are positioned in a parallel or substantially parallel relationship. More motors than rods could be present for backup purposes.

Please replace the paragraph beginning at page 13, line 18 through page 14, line 2, with the following rewritten paragraph:

In one embodiment, for example, the system for positioning guide members is used in conjunction with a web tracking unit. Referring to Figs. 11 and 12, 12A and 12B, a web tracking unit 175 is used to track the position of a web 113 as it moves right or left from the normal web path or position. The web tracking unit 175 is also used to maintain the position of the guide arms 111 in relation to the web 113. The web tracking unit 175 is placed up stream from the positioning apparatus 108 on a beam 176 of the frame of the web handling machine. The web handling machine supports spaced web guiding rollers 178, 179 and 180. As the web 113 passes the roller 179, the tracking unit 175 looks at the position of the web 113. The web tracking unit 175 includes a linear slide 182, supporting an arm 184 that supports a pair of sensors 185 and 186 that are spaced transversely or substantially transversely of the normal web path and that are spaced in the direction of movement of the web 113. The arm 184 is moved along the linear slide 182 by a servo motor 188. The linear slide 182 is supported from the beam 176, which also supports a cable track 189, which supports electrical cables (not shown). The servo motor 188 is coupled to a threaded rod 187 in the linear slide 182 and the threaded rod is connected to the arm 184. As formed, one spin of the threaded rod clockwise or counterclockwise moves the arm 184 10 millimeters and the encoder of the servo motor takes 4000 counts per revolution to precisely tell the position of the arm 184.

Please replace the paragraph beginning at page 14, line 3, with the following rewritten paragraph:

Referring now to Figs. ~~12~~ 12A, 12B and 13, the sensors 185 and 186 are formed of optical fibers. A laser light travels through each fiber and exits toward the web 113 on one side thereof. Light is reflected from the web 113 back to the fiber and is received by light receivers and sensor amplifiers 190 and 191, respectively. The sensors 185 and 186 have a built in alternating light source to avoid interference, or avoid one fiber from receiving reflected light from the other fiber. Again, each fiber is an emitter and receiver. The amplifiers 190 and 191 generate signals to the PLC of the positioning apparatus 108, which sends signals to the servo motor 188 to move the sensors, and then move the guide arms 111.